Autoregressive Modeling of LOD and UT1

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In this talk, a general stochastic model for UT1 and LOD will be proposed, and the corresponding Kalman filter model will be derived. This stochastic model consists of an arbitrary sum of general autoregressive moving average (ARMA) processes, each characterizing a different frequency band. This general formulat ion of the Kalman filter allows for experimentation and variability in choosing different stochastic models for UT], which in turn depends on the frequency band one wishes to model accurate] y, The general formulation can also be applied to various time series, including polar motion and AAM.

Based on the general formulation, several models for UT 1 were derived from spectra] analysis of the SPACE92 UT1 series (Gross, 1993). Using SPACE92 as the reference series, the candidate models were compared based on their ability to predict UT1 and LOD up to 30 days in the absence of data. These candidate models were compared with the JPL operational Kalman Earth Orientation Filter (KEOF) which assumes a random walk model for LOD (Morabito et al., 1987). The results of the comparison revealed that adding an AR 1 model to the random walk reduces the LOD prediction error by 10% to 20% during the first 30 days of prediction. A further reduction of the error can be achieved by autoregressive modeling of the 30-50 day oscillation in the LOD, in addition to the above random walk and AR1.

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